



(11) **EP 2 006 232 B1**

(12) **EUROPEAN PATENT SPECIFICATION**

(45) Date of publication and mention of the grant of the patent:
23.01.2019 Bulletin 2019/04

(21) Application number: **06731756.0**

(22) Date of filing: **13.04.2006**

(51) Int Cl.:
B66B 1/30 (2006.01)

(86) International application number:
PCT/JP2006/307820

(87) International publication number:
WO 2007/122676 (01.11.2007 Gazette 2007/44)

(54) **ELEVATOR DEVICE**
AUFZUGSVORRICHTUNG
DISPOSITIF ÉLÉVATEUR

(84) Designated Contracting States:
DE

(43) Date of publication of application:
24.12.2008 Bulletin 2008/52

(73) Proprietor: **MITSUBISHI ELECTRIC CORPORATION**
Chiyoda-ku
Tokyo 100-8310 (JP)

(72) Inventors:
• **UEDA, Takaharu**
Mitsubishi Electric Corporation
Tokyo 100-8310 (JP)

- **SHIBATA, Masunori**
Mitsubishi Electric Corporation
Tokyo 100-8310 (JP)
- **SAKAI, Masaya**
Mitsubishi Electric Corporation
Tokyo 100-8310 (JP)

(74) Representative: **Hoffmann Eitle**
Patent- und Rechtsanwälte PartmbB
Arabellastraße 30
81925 München (DE)

(56) References cited:
WO-A1-98/35903 **WO-A1-2006/006229**
JP-A- 2003 267 638 **JP-A- 2005 289 532**
JP-A- 2005 289 532

EP 2 006 232 B1

Note: Within nine months of the publication of the mention of the grant of the European patent in the European Patent Bulletin, any person may give notice to the European Patent Office of opposition to that patent, in accordance with the Implementing Regulations. Notice of opposition shall not be deemed to have been filed until the opposition fee has been paid. (Art. 99(1) European Patent Convention).

Description

Technical Field

[0001] The present invention relates to an elevator apparatus employing a plurality of hoisting machines to raise and lower a single car.

Background Art

[0002] In a conventional elevator control device, a speed pattern to be applied to a hoisting machine is changed based on a load of a car and a moving distance of the car, to thereby adjust acceleration of the car and a maximum speed of the car. That is, the acceleration of the car and the maximum speed of the car each are raised within respective allowable ranges of drive components such as a motor and an inverter, thereby being capable of shortening running time of the car (e.g., see Patent Document 1).

[0003] Patent Document 1: JP 2003-238037 A

Disclosure of the Invention

Problems to Be Solved by the Invention

[0004] In the conventional elevator control device configured as described above, or shown in JP 2005 289532, however, burdens on the drive components are increased in a case where there occurs a major detection error in the load of the car or a great loss during running. On the other hand, the potentials of the drive components cannot be brought out to the maximum when the speed pattern is determined in consideration of the detection error in the load or the loss during running. Further, the conventional elevator control device is designed to control a single hoisting machine, and hence cannot be applied to an elevator apparatus of such a type that a single car is raised and lowered by a plurality of hoisting machines.

[0005] The present invention has been made to solve the above-mentioned problems, and it is therefore an object of the present invention to obtain an elevator apparatus that makes it possible to operate drive components more efficiently and cause a car to run more stably by means of a plurality of hoisting machines. Means for solving the Problems

[0006] An elevator apparatus according to the present invention includes: a car; a plurality of hoisting machines for raising and lowering the car; and an elevator control device for controlling the hoisting machines, in which the elevator control device generates speed commands separately for the hoisting machines, and applies, when a current value of one of the hoisting machines reaches a current set value, which is set in advance during acceleration of the car, the speed command for that one of the hoisting machines whose current value is at or above the current set value, to the other hoisting machine as well.

[0007] Further, an elevator apparatus according to the present invention includes: a car; a plurality of hoisting machines for raising and lowering the car; and an elevator control device for controlling the hoisting machines, in which the elevator control device generates speed commands separately for the hoisting machines, and applies, when a voltage value which is applied to one of the hoisting machines reaches a voltage set value, which is set in advance during acceleration of the car, the speed command for that one of the hoisting machines whose voltage value is at or above the voltage set value, to the other hoisting machine as well.

Brief Description of the Drawings

[0008]

Fig. 1 is a schematic diagram showing an elevator apparatus according to Embodiment 1 of the present invention.

Fig. 2 is an explanatory diagram showing how a speed command generating section of Fig. 1 generates a speed command.

Fig. 3 is an explanatory diagram showing how a speed command changing section of Fig. 1 performs a speed command changing operation based on the monitoring of a current value.

Fig. 4 is an explanatory diagram showing how the speed command changing section of Fig. 1 performs a speed command changing operation based on the monitoring of a voltage value.

Fig. 5 is an explanatory diagram showing an example of a command signal for each of inverters of Fig. 1.

Fig. 6 is a schematic diagram showing an elevator apparatus according to Embodiment 2 of the present invention.

Best Mode for carrying out the Invention

[0009] Preferred embodiments of the present invention will be described hereinafter with reference to the drawings.

Embodiment 1

[0010] Fig. 1 is a schematic diagram showing an elevator apparatus according to Embodiment 1 of the present invention. A car 1, a first counterweight 2, and a second counterweight 3 are raised and lowered within a hoistway by a first hoisting machine 4 and a second hoisting machine 5. The first hoisting machine 4 has a first motor 6, a first drive sheave 7 that is rotated by the first motor 6, a first speed detector 8 for detecting a rotational speed of the first motor 6, and a first brake (not shown) for braking rotation of the first drive sheave 7.

[0011] The second hoisting machine 5 has a second motor 9, a second drive sheave 10 that is rotated by the second motor 9, a second speed detector 11 for detecting

a rotational speed of the second motor 9, and a second brake (not shown) for braking rotation of the second drive sheave 10. Employed as the first speed detector 8 and the second speed detector 11 are, for example, encoders, resolvers, or the like.

[0012] A plurality of first main ropes 12 (only one of the first main ropes 12 is illustrated in Fig. 1) for suspending the car 1 and the first counterweight 2 are wound around the first drive sheave 7. A plurality of second main ropes 13 (only one of the second main ropes 13 is illustrated in Fig. 1) for suspending the car 1 and the second counterweight 3 are wound around the second drive sheave 10.

[0013] The first motor 6 is supplied with a power from a power supply 16 via a first converter 14 and a first inverter 15. A first smoothing capacitor 17 is connected between the first converter 14 and the first inverter 15. A first regenerative resistor 18 and a first regenerative switch 19 are connected in parallel to the first smoothing capacitor 17. A value of a current supplied from the first inverter 15 to the first motor 6 is detected by a first current detector 20.

[0014] The second motor 9 is supplied with a power from a power supply 23 via a second converter 21 and a second inverter 22. A second smoothing capacitor 24 is connected between the second converter 21 and the second inverter 22. A second regenerative resistor 25 and a second regenerative switch 26 are connected in parallel to the second smoothing capacitor 24. A value of a current supplied from the second inverter 22 to the second motor 9 is detected by a second current detector 27.

[0015] Alternating voltages from the power supplies 16 and 23 each are converted into direct voltages by the converters 14 and 21 respectively and smoothed by the smoothing capacitors 17 and 24 respectively. The regenerative resistors 18 and 25 consume power regenerated during regenerative operation of the hoisting machines 4 and 5 as heat, respectively. Thus, when the voltage of each of the smoothing capacitors 17 and 24 exceeds a reference value, a corresponding one of the regenerative switches 19 and 26 is turned ON to cause a current to flow through a corresponding one of the resistors 18 and 25.

[0016] When each of the regenerative switches 19 and 26 is ON, the current flows through a corresponding one of the regenerative resistors 18 and 25, so the voltage of a corresponding one of the smoothing capacitors 17 and 24 drops. When the voltage of each of the smoothing capacitors 17 and 24 drops below a predetermined value, a corresponding one of the regenerative switches 19 and 26 is turned OFF, so supply of the current to a corresponding one of the regenerative resistors 18 and 25 is stopped. As a result, the voltage of each of the smoothing capacitors 17 and 24 is stopped from dropping.

[0017] As described above, the direct voltage input to each of the inverters 15 and 22 is controlled within a prescribed range by turning a corresponding one of the

regenerative switches 19 and 26 on and off in accordance with the voltage of a corresponding one of the smoothing capacitors 17 and 24. Employed as the regenerative switches 19 and 26 are, for example, semiconductor switches.

[0018] The first inverter 15 and the second inverter 22 are controlled by an elevator control device 31. That is, operations of the first hoisting machine 4 and the second hoisting machine 5 are controlled by the elevator control device 31. The elevator control device 31 has a first hoisting machine control section 32 for controlling the operation of the first hoisting machine 4, a second hoisting machine control section 33 for controlling the operation of the second hoisting machine 5, and a speed command changing section 34.

[0019] The first hoisting machine control section 32 has a first speed command generating section 35, a first speed control section 36, and a first current control section 37. The first speed command generating section 35 generates a speed command for the car 1, namely, a speed command for the first hoisting machine 4 in accordance with registrations of calls from landings or calls from within the car 1.

[0020] The first speed control section 36 calculates a torque value and generates a torque command such that the rotational speed of the first motor 6 coincides with the value of the speed command, based on the speed command generated by the first speed command generating section 35 and information from the first speed detector 8.

[0021] The first current control section 37 controls the first inverter 15 based on a current detection signal from the first current detector 20 and the torque command from the first speed control section 36. More specifically, the first current control section 37 converts the torque command from the first speed control section 36 into a current command value, and outputs a signal for driving the first inverter 15 such that a value of the current detected by the first current detector 20 coincides with the current command value.

[0022] The second hoisting machine control section 33 has a second speed command generating section 38, a second speed control section 39, and a second current control section 40. The second speed command generating section 38 generates a speed command for the car 1, namely, a speed command for the second hoisting machine 5 in accordance with registrations of calls from the landings or calls from within the car 1.

[0023] The second speed control section 39 calculates a torque value and generates a torque command such that the rotational speed of the second motor 9 coincides with the value of the speed command, based on the speed command generated by the second speed command generating section 38 and information from the second speed detector 11.

[0024] The second current control section 40 controls the second inverter 22 based on a current detection signal from the second current detector 27 and the torque

command from the second speed control section 39. More specifically, the second current control section 40 converts the torque command from the second speed control section 39 into a current command value, and outputs a signal for driving the second inverter 22 such that a value of the current detected by the second current detector 27 coincides with the current command value.

[0025] Vector control is adopted in controlling the currents flowing through the inverters 15 and 22 by means of the current control sections 37 and 40 respectively. That is, each of the current control sections 37 and 40 calculates a voltage value to be output by a corresponding one of the inverters 15 and 22 in accordance with the current command value obtained through conversion of the torque command and the current value of a corresponding one of the motors 6 and 9 and a magnetic pole position (a rotational position) thereof, which has been detected by a corresponding one of the current detectors 20 and 27, and outputs an on and off switching pattern to a transistor as a built-in component in the corresponding one of the inverters 15 and 22.

[0026] Each of the speed command generating sections 35 and 38 generates a speed command separately for a corresponding one of the hoisting machines 4 and 5 so as to raise the maximum speed of the car 1 and the acceleration of the car 1 to the maximum possible extent within allowable ranges of drive components (the motors 6 and 9 and electric components for driving the motors 6 and 9) and hence shorten the running time of the car 1.

[0027] The speed command changing section 34 monitors the current values input to the motors 6 and 9 from the inverters 15 and 22 respectively and the values of applied voltages (inverter command values) calculated by the current control sections 37 and 40 respectively, and prevents the first speed command generating section 35 and the second speed command generating section 38 from generating different speed commands.

[0028] More specifically, when one of the current values input to the motors 6 and 9 reaches a current set value, which is set in advance during acceleration of the motors 6 and 9, the speed command changing section 34 thereafter changes the speed command value of that one of the speed command generating sections 35 and 38, which is on the side where the current set value has not been reached, into the same value as the speed command value generated by that one of the speed command generating sections 35 and 38 which is on the side where the current set value has been reached.

[0029] Further, when one of the applied voltage values calculated by the first current control section 37 and the second current control section 40 reaches a voltage set value, which is set in advance during acceleration of the motors 6 and 9, the speed command changing section 34 thereafter changes the speed command value of that one of the speed command generating sections 35 and 38, which is on the side where the voltage set value has not been reached, into the same value as the speed command value generated by that one of the speed command

generating sections 35 and 38 which is on the side where the voltage set value has been reached.

[0030] It should be noted herein that the elevator control device 31 is constituted by a computer having a calculation processing section (a CPU), a storage section (a ROM, a RAM, a hard disk, and the like), and signal input/output sections. That is, the functions of the speed command changing section 34, the speed command generating sections 35 and 38, the speed control sections 36 and 39, and the current control sections 37 and 40 are realized by the computer.

[0031] Fig. 2 is an explanatory diagram showing how the speed command generating section 35 of Fig. 1 generates a speed command. Referring to Fig. 2, a graph (a) shows an example of time-based changes in speed command value. A graph (b) shows time-based changes in the acceleration of the car 1 which correspond to the graph (a). A graph (c) shows time-based changes in the applied voltage value output from the current control section 37. A graph (d) shows time-based changes in the current value input to the motor 6.

[0032] According to the speed command indicated by the graph (a), the motor 6 is activated with a jerk j_1 [m/s^3] (a derivative value of the acceleration of the graph (b)) at, for example, a time t_0 . After that, the acceleration of the car 1 is raised with the jerk j_1 [m/s^3] until a time t_1 at which the current value indicated by the graph (d) reaches a current set value I_0 . The jerk is held equal to 0 after the time t_1 , and the car 1 is accelerated with a constant acceleration until a time t_2 at which the voltage value indicated by the graph (c) reaches a voltage set value V_0 .

[0033] The speed command is generated with a jerk j_2 [m/s^3] from the time t_2 to a time t_3 so as to ensure a smooth transition at constant-speed running. After the time t_3 , a time t_4 corresponding to the end of constant-speed running and a time t_5 corresponding to the completion of running are determined in accordance with a running distance required for the car 1, a preset deceleration β [m/s^2], a jerk j_3 [m/s^3] during deceleration from constant-speed running, and a jerk j_4 [m/s^3] during a transition from constant-deceleration running to a stoppage of running, so a speed pattern is generated.

[0034] The method of generating the speed command as described above is also adopted by the speed command generating section 38. It should be noted herein that the current set value I_0 and the voltage set value V_0 are set such that allowable limit values for the motors 6 and 9 and the electric components for driving the motors 6 and 9, for example, power-supply capacities and allowable currents for the inverters 15 and 22, are not exceeded.

[0035] Fig. 3 is an explanatory diagram showing how the speed command changing section 34 of Fig. 1 performs a speed command changing operation based on the monitoring of a current value. Referring to Fig. 3, a graph (a) shows an example of time-based changes in speed command value. A graph (b) shows time-based changes in the current value of the second hoisting ma-

chine 5 (the second motor 9). A graph (c) shows time-based changes in the current value of the first hoisting machine 4 (the first motor 6).

[0036] According to the speed command indicated by the graph (a), the hoisting machines 4 and 5 are activated to start accelerating the car 1 at the time t_0 . After that, the current value of the second hoisting machine 5 reaches the current set value I_0 at the time t_1 . On the other hand, the current value of the first hoisting machine 4 reaches the current set value I_0 at the time t_2 , which is preceded by the time t_1 . That is, in the example of Fig. 3, the current value of the second hoisting machine 5 reaches the current set value I_0 before the current value of the first hoisting machine 4 reaches the current set value I_0 .

[0037] Thus, the speed command changing section 34 changes the speed command value of the first speed command generating section 35 (as indicated by broken lines of the graph (a)) into the speed command value generated by the second speed command generating section 38 (as indicated by a solid line of the graph (a)).

[0038] Fig. 4 is an explanatory diagram showing how the speed command changing section 34 of Fig. 1 performs a speed command changing operation based on the monitoring of a voltage value. Referring to Fig. 4, a graph (a) shows an example of time-based changes in speed command value. A graph (b) shows time-based changes in the value of the voltage applied to the second hoisting machine 5. A graph (c) shows time-based changes in the value of the voltage applied to the first hoisting machine 4.

[0039] According to the speed command of the graph (a), the hoisting machines 4 and 5 are activated to start accelerating the car 1 at the time t_0 . After that, the value of the voltage applied to the second hoisting machine 5 reaches the voltage set value V_0 at the time t_2 . On the other hand, the value of the voltage applied to the first hoisting machine 4 reaches the voltage set value V_0 at the time t_3 , which is preceded by the time t_2 . That is, in the example of Fig. 4, the value of the voltage applied to the second hoisting machine 5 reaches the voltage set value V_0 before the value of the voltage applied to the first hoisting machine 4 reaches the voltage set value V_0 .

[0040] Thus, the speed command changing section 34 changes the speed command value of the first speed command generating section 35 (as indicated by broken lines of the graph (a)) into the speed command value generated by the second speed command generating section 38 (as indicated by a solid line of the graph (a)).

[0041] In the elevator apparatus configured as described above, the drive components can be more efficiently operated without being affected by a detection error in the load of the car 1 or a loss caused during running. Further, the speed commands for the first hoisting machine 4 and the second hoisting machine 5 can be prevented from becoming different from each other, so the car 1 can be caused to run stably by the two hoisting machines 4 and 5.

[0042] In the foregoing example, the single elevator control device 31 performs the functions of the first hoisting machine control section 32, the second hoisting machine control section 33, and the speed command changing section 34. However, the elevator control device 31 may be divided into a plurality of control devices to perform those functions respectively.

[0043] Further, separate speed command changing sections may be employed to monitor a current and a voltage individually.

[0044] Still further, in the foregoing example, the voltage values calculated by the current control sections 37 and 40 are monitored by the speed command changing section 34. However, a duty value as a ratio of an ON time period of each of the inverters 15 and 22 within a predetermined time period may be monitored instead.

[0045] Now, Fig. 5 is an explanatory diagram showing an example of a command signal for each of the inverters 15 and 22 of Fig. 1. The ratio of the ON time period of each of the inverters 15 and 22 within a sampling time cycle T increases as the speed of the car 1 increases after the car 1 has started running. The duty value, which is calculated as $\Delta t_i/T$, is proportional to the voltage applied to a corresponding one of the hoisting machines 4 and 5. Accordingly, the same control as in Embodiment 1 of the present invention can also be performed by monitoring the current flowing through each of the hoisting machines 4 and 5 and the duty value.

Embodiment 2

[0046] Next, Fig. 6 is a schematic diagram showing an elevator apparatus according to Embodiment 2 of the present invention. Referring to Fig. 6, an elevator control device 41 has the first hoisting machine control section 32, the second hoisting machine control section 33, and a communication section 42. Information can be transmitted between the first speed command generating section 35 and the second speed command generating section 38 via the communication section 42.

[0047] The first speed command generating section 35 monitors whether or not the applied voltage value calculated by the first current control section 37 reaches a voltage set value during acceleration of the first motor 6, and whether or not a current value input to the first motor 6 from the first inverter 15 reaches a current set value during acceleration of the first motor 6.

[0048] The second speed command generating section 38 monitors whether or not the applied voltage value calculated by the second current control section 40 reaches a voltage set value during acceleration of the second motor 9, and whether or not a current value input to the second motor 9 from the second inverter 22 reaches a current set value during acceleration of the second motor 9.

[0049] When the current value reaches the current set value, a corresponding one of the speed command generating sections 35 and 38 transmits the information in-

dicative thereof to the other speed command generating section 35 or 38 on the side where the current set value has not been reached. Upon receiving the information indicating that the current value has reached the current set value, the speed command generating section 35 or 38 changes the speed command value thereof into the same value as the speed command value generated by the other speed command generating section 35 or 38 on the side where the current set value has been reached.

[0050] In addition, when the voltage value reaches the voltage set value, a corresponding one of the speed command generating sections 35 and 38 transmits the information indicative thereof to the other speed command generating section 35 or 38 on the side where the voltage set value has not been reached. Upon receiving the information indicating that the voltage value has reached the voltage set value, the speed command generating section 35 or 38 changes the speed command value thereof into the same value as the speed command value generated by the other speed command generating section 35 or 38 on the side where the voltage set value has been reached. Embodiment 2 of the present invention is identical to Embodiment 1 of the present invention in other configurational details.

[0051] As described above, the speed command generating sections 35 and 38 may be configured to transmit monitoring results of current and voltage to each other. In this manner, a simplification in configuration can be achieved through the omission of the speed command changing section 34 of Embodiment 1 of the present invention.

[0052] A function of the elevator control device 41 of Embodiment 2 of the present invention may be performed by either a single device or a plurality of separate devices.

[0053] In each of the foregoing examples, the converters 14 and 21 and the power supplies 16 and 23 are employed as the components corresponding to the first hoisting machine 4 and the second hoisting machine 5 respectively. However, a common converter and a common power supply may be employed for the first hoisting machine 4 and the second hoisting machine 5.

[0054] Further, the present invention is also applicable to an elevator apparatus employing three or more hoisting machines to raise and lower a single car.

[0055] Still further, in each of the foregoing examples, the jerk is regarded as a constant for convenience of explanation. However, the jerk may be a function of time. In this case, a reduction in running time and an improvement to obtain a comfortable ride can be achieved.

[0056] No particular limitation should be imposed on the roping method.

[0057] Further, each of the main ropes 12 and 13 may be designed as either a rope having a circular cross-section or a belt-shaped rope having a flat cross-section.

[0058] Still further, in each of the foregoing examples, the speed control of the first hoisting machine 4 and the second hoisting machine 5 is performed by the computer. However, this speed control can also be performed by a

circuit for processing analog electric signals.

Claims

1. An elevator apparatus, comprising:
 - a car (1);
 - a plurality of hoisting machines (4, 5) for raising and lowering the car (1); and
 - an elevator control device (31, 41) for controlling the hoisting machines (4, 5),
 wherein the elevator control device (31, 41) generates speed commands separately for the hoisting machines (4, 5), and applies, when a current value of one of the hoisting machines (4, 5) reaches a current set value, which is set in advance during acceleration of the car (1), the speed command for that one of the hoisting machines (4, 5), whose current value is at or above the current set value, to the other hoisting machine (4, 5) as well.
2. The elevator apparatus according to Claim 1, wherein the elevator control device (31, 41) changes a jerk in each of the speed commands into 0 when the current value of a corresponding one of the hoisting machines (4, 5) reaches the current set value during acceleration of the car (1).
3. An elevator apparatus, comprising:
 - a car (1);
 - a plurality of hoisting machines (4, 5) for raising and lowering the car (1); and
 - an elevator control device (31, 41) for controlling the hoisting machines (4, 5),
 wherein the elevator control device (31, 41) generates speed commands separately for the hoisting machines (4, 5), and applies, when a voltage value, which is applied to one of the hoisting machines (4, 5), reaches a voltage set value, which is set in advance during acceleration of the car (1), the speed command for that one of the hoisting machines (4, 5), whose voltage value is at or above the voltage set value, to the other hoisting machine (4, 5) as well.
4. The elevator apparatus according to Claim 3, wherein the elevator control device (31, 41) shifts a running state of the car (1) to constant-speed running when the value of the voltage applied to one of the hoisting machines (4, 5) reaches the voltage set value during acceleration of the car (1).

Patentansprüche**1.** Eine Aufzugsvorrichtung, umfassend:

eine Kabine (1);
 eine Vielzahl von Hebemaschinen (4, 5) zum Anheben und Absenken der Kabine (1); und
 eine Aufzugs-Steuereinrichtung (31, 41) zum Steuern der Hebemaschinen (4, 5),
 wobei die Aufzugs-Steuereinrichtung (31, 41) Geschwindigkeitsbefehle separat für die Hebemaschinen (4, 5) erzeugt und, wenn ein Stromwert von einem der Hebemaschinen (4, 5) einen Strom-Sollwert erreicht, der im Voraus während einer Beschleunigung der Kabine (1) gesetzt wird, den Geschwindigkeitsbefehl für den einen der Hebemaschinen (4, 5), dessen Stromwert bei oder über dem Strom-Sollwert ist, auch für die anderen Hebemaschinen (4, 5) anwendet.

2. Die Aufzugsvorrichtung gemäß Anspruch 1, wobei die Aufzugs-Steuereinrichtung (31, 41) einen Ruck in jedem der Geschwindigkeitsbefehle in 0 ändert, wenn der Stromwert von einer entsprechenden der Hebemaschinen (4, 5) den Strom-Sollwert während einer Beschleunigung der Kabine (1) erreicht.

3. Eine Aufzugsvorrichtung, umfassend:

eine Kabine (1);
 eine Vielzahl von Hebemaschinen (4, 5) zum Anheben und Absenken der Kabine (1); und
 eine Aufzugs-Steuereinrichtung (31, 41) zum Steuern der Hebemaschinen (4, 5),
 wobei die Aufzugs-Steuereinrichtung (31, 41) Geschwindigkeitsbefehle separat für die Hebemaschinen (4, 5) erzeugt und, wenn ein Spannungswert, der an eine der Hebemaschinen (4, 5) angewendet wird, einen Spannungs-Sollwert erreicht, der im Voraus während einer Beschleunigung der Kabine (1) gesetzt wird, den Geschwindigkeitsbefehl für den einen der Hebemaschinen (4, 5), dessen Spannungswert bei oder über dem Spannungs-Sollwert ist, auch für die anderen Hebemaschinen (4, 5) anwendet.

4. Die Aufzugsvorrichtung gemäß Anspruch 3, wobei die Aufzugs-Steuereinrichtung (31, 41) einen Betriebszustand der Kabine (1) auf einen Betrieb konstanter Geschwindigkeit verschiebt, wenn der auf eine der Hebemaschinen (4, 5) angewendete Wert der Spannung den Spannungs-Sollwert während einer Beschleunigung der Kabine (1) erreicht.

une cabine (1) ;
 une pluralité de machines de levage (4, 5) pour lever et abaisser la cabine (1) ; et
 un dispositif de commande d'élévateur (31, 41) pour la commande des machines de levage (4, 5),
 dans lequel le dispositif de commande d'élévateur (31, 41) génère des instructions de vitesse séparément pour les machines de levage (4, 5), et applique, lorsqu'une valeur de courant d'une des machines de levage (4, 5) atteint une valeur de courant réglée, qui est réglée en avance pendant l'accélération de la cabine (1), l'instruction de vitesse pour celle des machines de levage (4, 5) dont la valeur de courant est à ou au-dessus de la valeur de courant réglée, à l'autre machine de levage (4, 5) également.

2. Dispositif élévateur selon la revendication 1, dans lequel le dispositif de commande d'élévateur (31, 41) change une suraccélération dans chacune des instructions de vitesse à 0 lorsque la valeur de courant d'une correspondante des machines de levage (4, 5) atteint la valeur de courant réglée pendant l'accélération de la cabine (1).

3. Dispositif élévateur comprenant :

une cabine (1) ;
 une pluralité de machines de levage (4, 5) pour lever et abaisser la cabine (1) ; et
 un dispositif de commande d'élévateur (31, 41) pour la commande des machines de levage (4, 5),
 dans lequel le dispositif de commande d'élévateur (31, 41) génère des instructions de vitesse séparément pour les machines de levage (4, 5), et applique, lorsqu'une valeur de tension, qui est appliquée à une des machines de levage (4, 5), atteint une valeur de tension réglée, qui est réglée en avance pendant l'accélération de la cabine (1), l'instruction de vitesse pour celle des machines de levage (4, 5) dont la valeur de tension est à ou au-dessus de la valeur réglée de tension, à l'autre machine de levage (4, 5) également.

4. Dispositif élévateur selon la revendication 3, dans lequel le dispositif de commande d'élévateur (31, 41) décale un état de fonctionnement de la cabine (1) à un fonctionnement à vitesse constante lorsque la valeur de la tension appliquée à une des machines de levage (4, 5) atteint la valeur de tension réglée pendant l'accélération de la cabine (1).

Revendications**1.** Dispositif élévateur comprenant :

FIG. 1

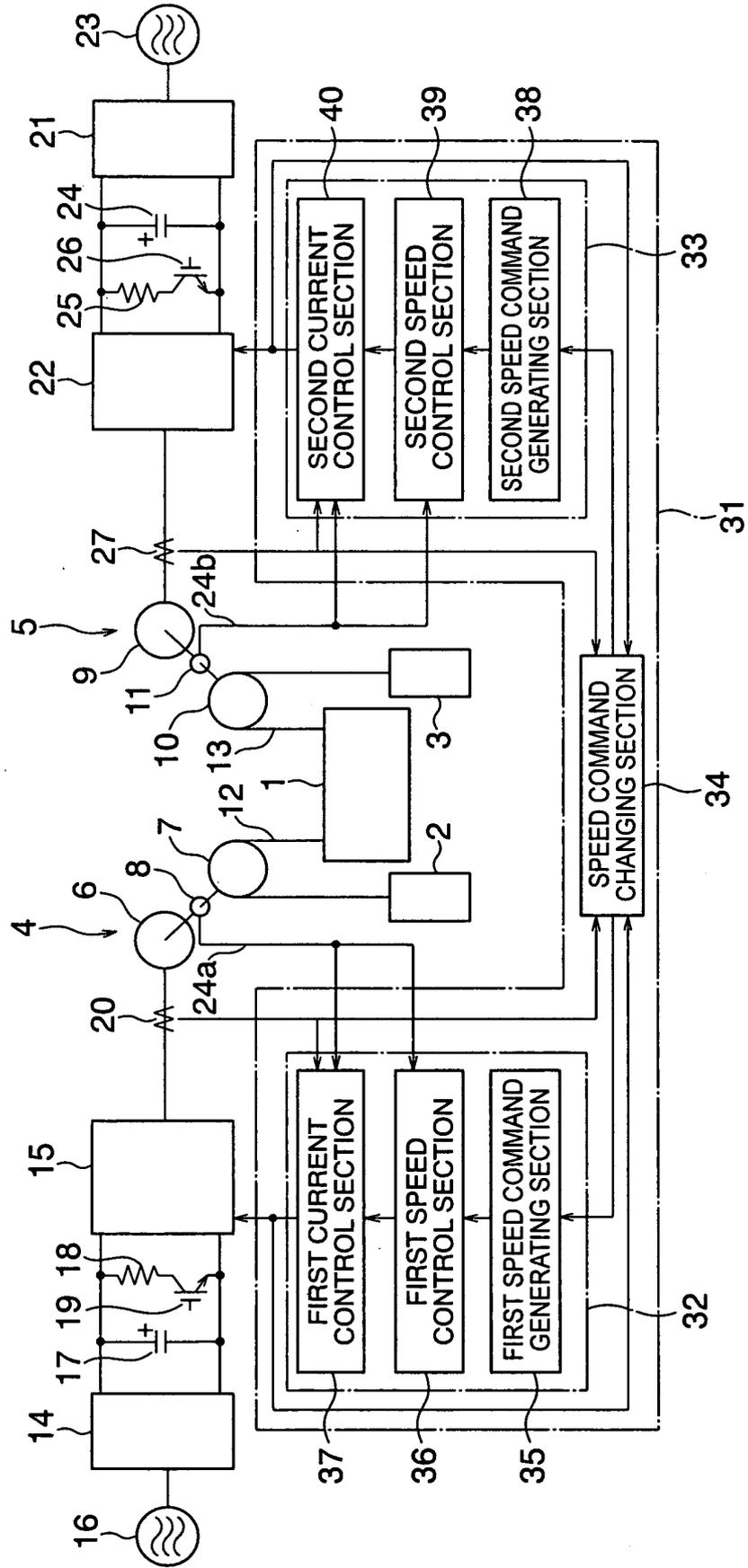


FIG. 2

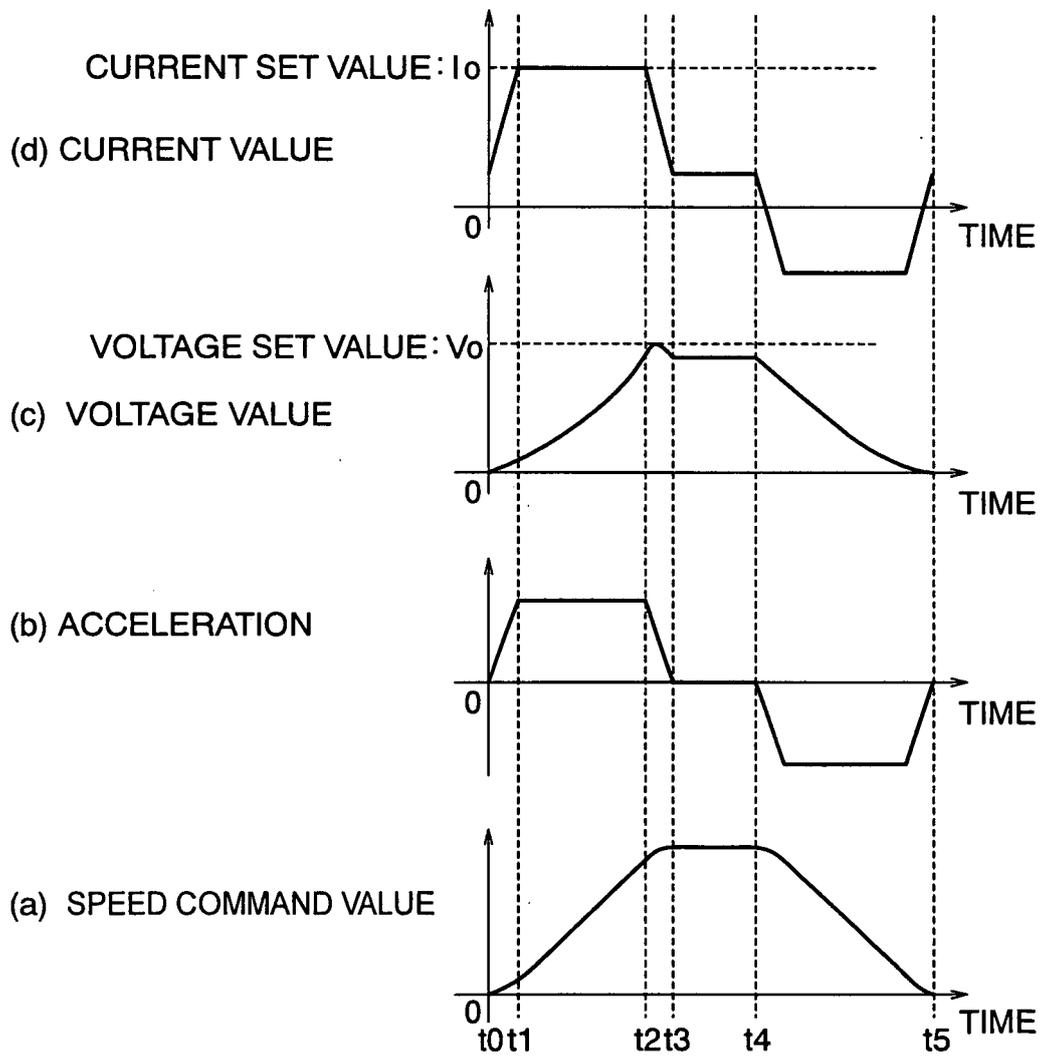


FIG. 3

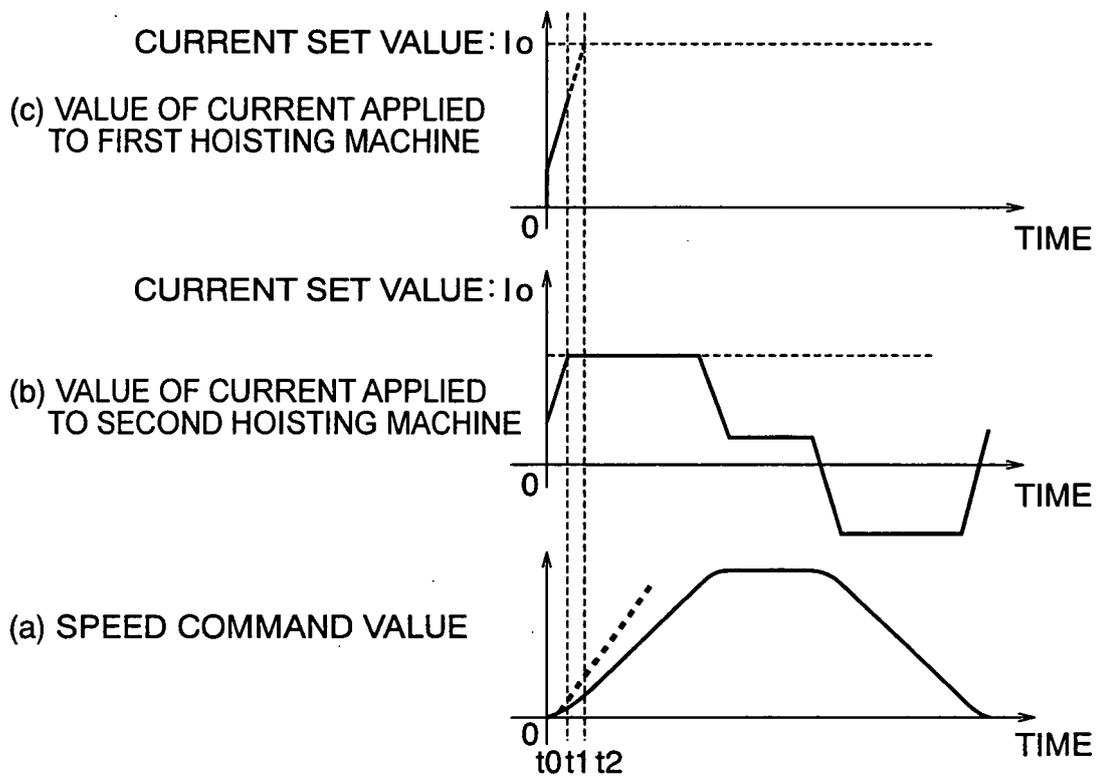


FIG. 4

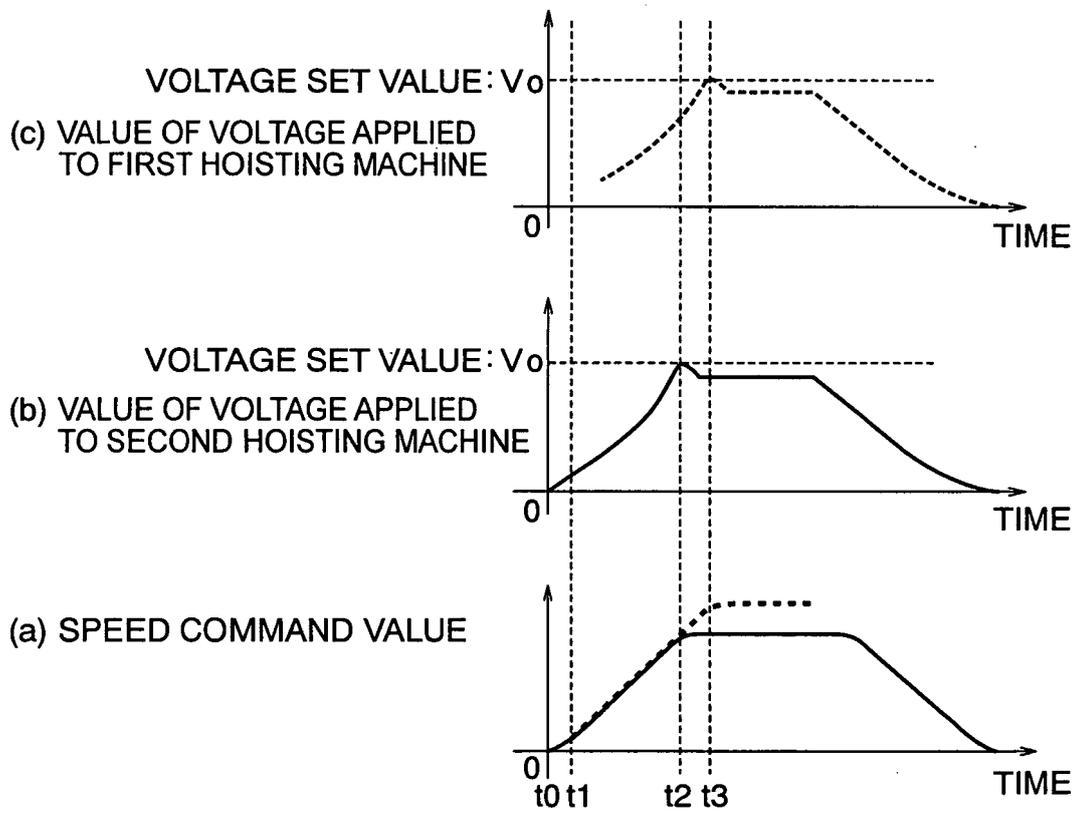


FIG. 5

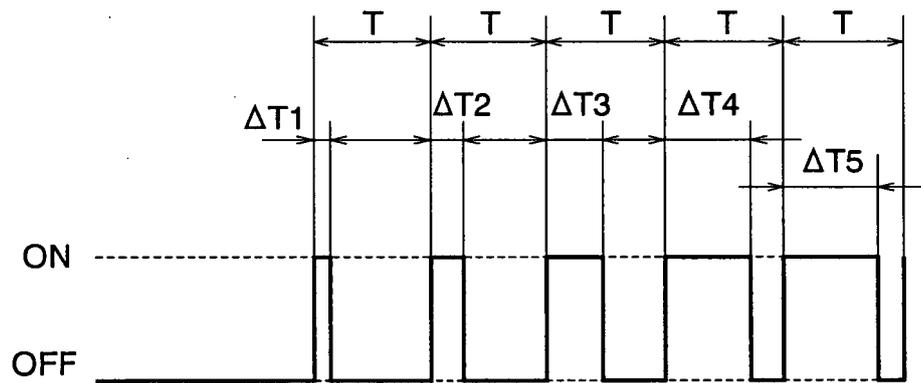
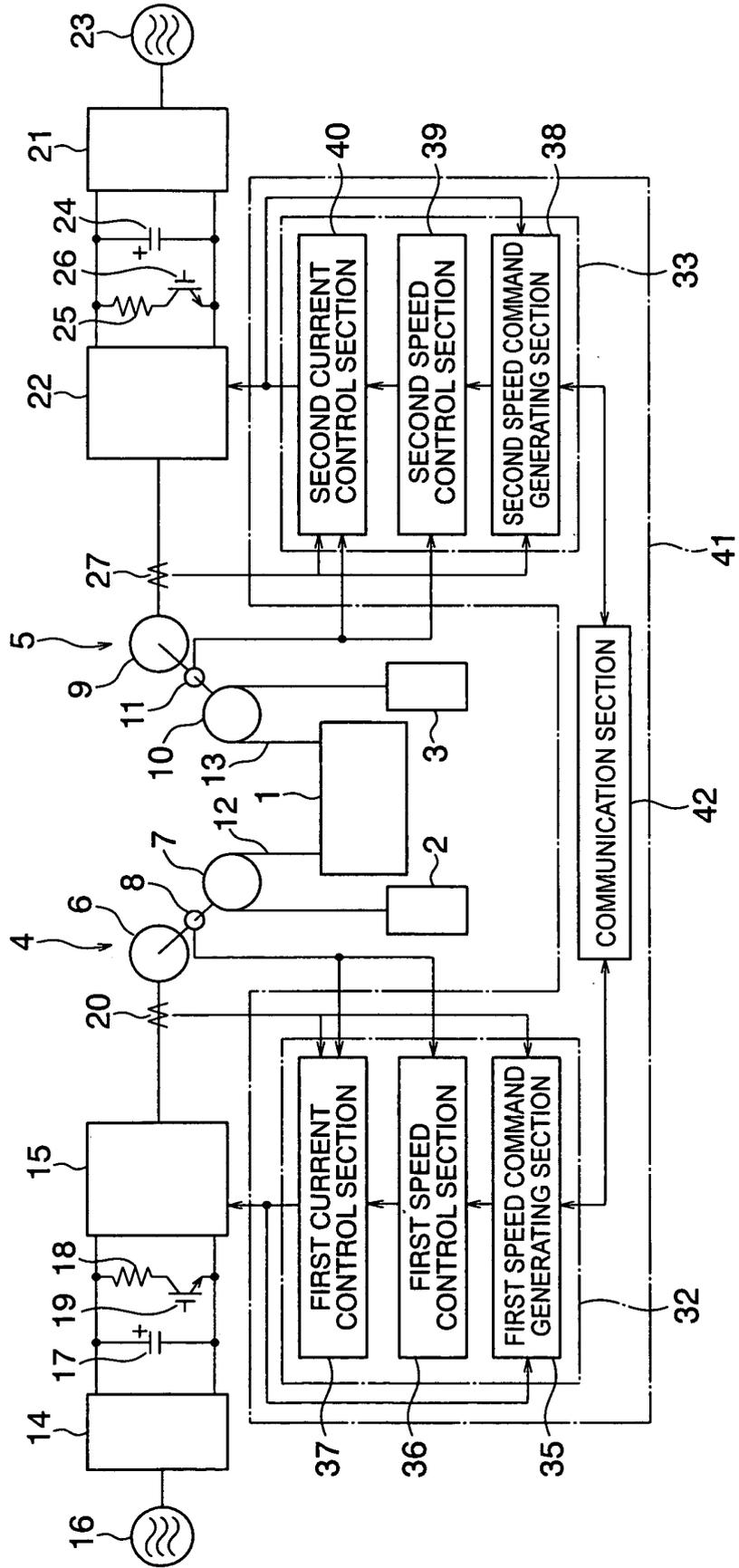


FIG. 6



REFERENCES CITED IN THE DESCRIPTION

This list of references cited by the applicant is for the reader's convenience only. It does not form part of the European patent document. Even though great care has been taken in compiling the references, errors or omissions cannot be excluded and the EPO disclaims all liability in this regard.

Patent documents cited in the description

- JP 2003238037 A [0003]
- JP 2005289532 A [0004]